

SCANNING LARGE AEROSPACE STRUCTURES USING OPEN-ARCHITECTURE CRAWLERS

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ABSTRACT

The determination of the integrity of complex large metallic and composite structures requires cost-effective rapid inspection capability. Removing components from a structure for NDE at an inspection facility is not economical. Detection and characterization of defects are labor intensive, time consuming and when the process is manual the results are vulnerable to human error. These limitations of NDE created a need for portable, user friendly inspection systems that can rapidly scan large areas of complex structures and locate all the detrimental conditions. Addressing this need has been an evolutionary process that followed the technology trend, and unique devices were developed to allow rapid field inspection. This development involves multidisciplinary approaches to integrate NDE, robotics, neural networks, materials science, imbedded computing and automated control. These efforts have led to various portable inspection systems and the current trend is towards fully automatic systems that will operate autonomously. To support the need for effective portable robotic system the authors developed the multifunction automated crawling system (MACS) offering an open architecture robotic platform for NDE boards and sensors. This crawler enabled the technology of "walking" computer platforms with standard plug-in NDE boards. This capability offers a larger pool of companies and individuals to become potential producers of NDE instruments. Thus, a significant cost reduction can be materialized with a rapid transition of novel concepts to practical use. The capability and potential of MACS as an enabling technology will be discussed in this paper.

INTRODUCTION

Inspection of aircraft in service requires rapid on-site examination rather than removal of parts for a lab test. Manual field inspection is labor-intensive, time consuming, demands great attention to details by the inspectors and it is subject to human errors. The interpretation of the data depends critically on the inspectors' experience, competence, attentiveness and meticulous dedication. For instance, rivet crack inspection using eddy

current is known to be a mundane and painstaking task, which can lead to a significant decrease in the inspector attention during a long inspection session. Disassembly of structures and inspection in laboratory conditions offer a greater reliability of the test results, however it is costly and, in many cases, is not a practical approach. The limitations of field inspection are hampering the growth in usage of composite structures for construction of aircraft since they require more often an inspection of large areas. This is due to the fact that composite structures are sensitive to impact damage in service, which can occur at any point and any time. To overcome the limitations of field NDE methods, scanners are being developed to perform automatic and rapid scanning of large and complex-shape structures. For military aircraft, in addition to the desire to increase the speed and reliability of the inspection, there is a need in some applications to operate at harsh, hostile and/or remote conditions (extreme temperature, battlefield, remote expertise, etc.).

Since the introduction of microprocessors, various types of portable scanners were developed using such NDE methods as visual, eddy currents, ultrasonics, shearography, radiography and thermography. While most scanners have been dedicated to a single inspection method, there is an overall trend to combine the capability of more than one inspection method. Increasingly such a multi-mode option is becoming commercially available and systems, such as the MAUS (Boeing, St. Louis, MO), are offering interchangeable components to perform more than one test method [Bar-Cohen, 2000]. While not applied simultaneously yet, the leading NDE methods that are used in such scanners include mostly eddy current and ultrasonics. Efforts are being made to add also a visual inspection capability.

Corrosion in aging aircraft was recognized as a serious issue for the military since many aircraft models have been in service for 25-40 years and there is an effort to use them for 40 more years. The cost of corrosion to DoD is estimated at \$1B and it needs to be effectively reduced. While it is a costly item, corrosion as a flaw does not lead to aircraft fleet grounding unless it is expected to cause the development of a crack, which in most cases is a slow process. NATIBO's two-year study, entitled Corrosion Detection Technologies Insertion Program Selection, resulted from the recognition of the effect of corrosion on the resources of these departments of defense and on the durability of their existing aircraft systems. Some of the issues are the result of budget reduction, loss of manpower leading to loss of "corporate memory", and restrictions as a result of environmental concerns. It was determined that there is a need for rapid inspection of large areas, accounting for the different corrosion types, increasing the Probability Of Detection (POD), lower cost of operation, reduce aircraft downtime and increase mission readiness. The developed technology needs to leverage commercial capabilities, have multiple applications, be easy to use, operate rapidly and have an open architecture. Following this study, it was concluded that there are three technologies that need to be addressed more closely including a) multi sensors, b) sensor fusion and c) robotic inspection. Three specific methods were recognized as the most effective for corrosion including

- a) Edge of light technique, which is a highly sensitive visual technique developed recently by the Canadian National Research Council [Forsyth, et al, 1998].
- b) Eddy Current - This method is widely in use in aircraft inspection and recent studies of pulsed eddy current has been encouraging to consider this emerging approach [Lepine, et al, 1998].
- c) Ultrasonics - This method is also widely in use for detection of corrosion. To address the need for a couplant, the Iowa State University dripless bubbler was recommended as an effective coupling alternative [Patton and Hsu, 1996].

The recently developed multifunction automated crawling system (MACS) offered enabling technology of simultaneously using several NDE methods that are operated by a single scanner. Such a crawler can travel on an aircraft structure and automatically perform inspection tasks that can be controlled remotely over a modem or the Internet. As the technology evolves, crawlers would be developed to operate autonomously and search for flaws on aircraft structures without a human interference. Effectively, MACS is a robotic platform which can be used to integrate a suite of sensors and to perform intelligent scanning and testing aircraft for corrosion and other defects. This paper reviews the technology evolution towards using robotic inspection, the recently developed capability, the expected development direction and the role that intelligent NDE can play [Bar-Cohen, 2000, and Backes & Bar-Cohen, 1996].

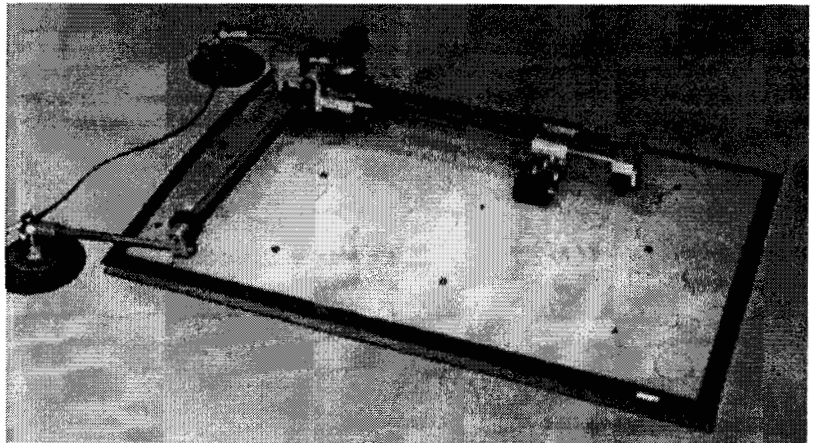
RAPID INSPECTION SCANNERS

Nondestructive evaluation techniques can be distinguished by their ability to provide information about a specific location or a large area in a single test. Radiography, Thermography, Shearography, Magnetic Particles and Liquid Penetrant are providing defect information about an area. On the other hand, sensor base methods that include ultrasonics and eddy-current are requiring scanning in order to provide defect information in a desired area. Otherwise, the obtained data are limited to the specific location that is as small as the probe area or less. For a limited area of centimeters in size, transducer arrays were introduced to allow electronic scanning for rapid imaging as in medical ultrasonics, whereas for larger areas mechanical scanning is used. Over the last four decades, scanners were developed to support ultrasonic inspections to produce B-scan and C-scan images. Generally, the development of scanners made the biggest impact on the wide use of ultrasonics because scanners allowed the production of detailed images of the flaws size and location. Moreover, these scanners offered a form of documenting test results, allowed consistent data acquisition capability, and offered a simplified acceptance/rejection approach. In recent years, significant progress has been made in the area of eddy-current scanners allowing imaging of eddy current C-scan data. For a long time, the automated inspection capability (also known as C-scan) was available only for lab conditions and field inspection was performed manually. The emergence of microprocessors enabled lab systems that are capable of contour-following of structures by meeting the sensitivity requirements of ultrasonic tests to having the beam normal to the surface. Also, systems were to operate in concurrence with detailed CAD drawings. Since the early 80's, automatic C-scan systems have emerged with the capability to inspect full aircraft structures, such as the wing of the Harrier aircraft.

With the evolution of personal computers and microelectronics, it became possible to produce portable C-scanners that can operate in depot and field conditions [Bar-Cohen, 2000, and Backes & Bar-Cohen, 1996]. The original portable scanners were relatively heavy and consisted of a simple bridge that can be carried to the field in a mobile set of boxes to perform scanning, data acquisition, imaging and storage. To support the formation of the C-scan images, encoding methods were developed to identify the probe location while operating on aircraft structures. Such position encoding methods included the use of acoustic waves, as in the ISIS system that was developed in the early 80's by General Dynamics under an Air Force contract, optical scales and other encoding techniques. Due to the inaccuracy of the acoustic encoding technique it was phased out and most of the current portable scanners rely on optical encoders. To inspect vertical surfaces and upside down surfaces of aircraft wings, strapping techniques and vacuum cups are used to attach the portable C-scan bridge to the test area. An example of a portable scanner that uses vacuum cups to secure its attachment to the test structure is shown in Figure 1.

The introduction of portable C-scan bridges enabled to semi-automation of the ultrasonic field inspection and to significantly improve the reliability of such field tests. Since aircraft structures have a complex geometry, the use of a flat rigid C-scan bridge faces difficulties associated with the gap between the flat surface of the bridge and the curved surface of the aircraft. The PANDA Scanner (made by Tektrend, Quebec, Canada) followed by MAUS (Boeing, St. Louis, CA) and others addressed this issue by employing a flexible arm. Being a contact-scanning device, the PANDA's spring-loaded transducer holder has the flexibility to follow the contour of an aircraft structure. The arm can be flexed to adapt the bridge curvature to the surface contour of the aircraft and thus ensuring the transducer contact to test surface during scanning.

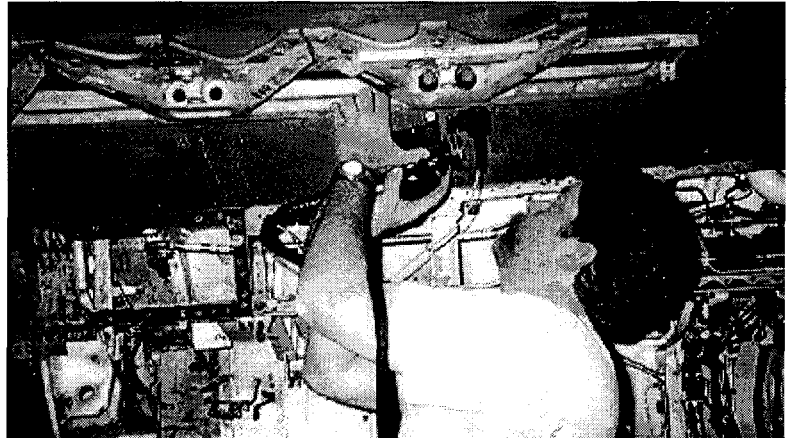
Figure 1: A scanner using a portable bridge and two suction cups to secure the bridge position during scan (made by QMI, Costa Mesa, CA).



Considering the limitation of stationary scanners, the McDonnell Douglas Corp. (prior to being acquired by Boeing) developed at the end of the 1980's a scanner called MAUS that allows semi-mobile scanning. MAUS uses a hand-held scanners that translates a series of probes sideways while an operator is responsible for moving the scanner head forward and backward. Recent modification of the MAUS, the PANDA and other

scanner enabled the alternate use of either an ultrasonics or eddy current head. A photographic view of the MAUS in use by an operator is shown in Figure 2. Unfortunately, the need to manually position the scanner head can be a tiring task when inspecting vertical or upside down surfaces. To address this constraint, the MAUS probe mount was modified to allow an attached bridge that uses suction cups and can be sequentially moved to cover the desired test area.

Figure 2: A view of the application of MAUS and the hand-held probe in a field test.



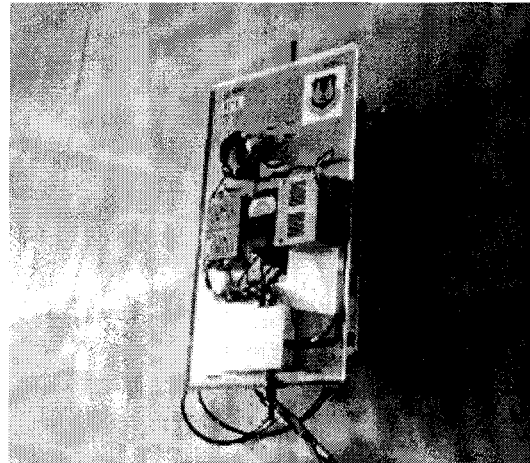
Generally, current scanners cover a limited area in a single scanning session that is defined by the scanner-bridge dimensions. Covering a large area of an aircraft requires multiple scans where the operator moves the scanner bridge from one location to another in the form of scan-tiles as the full structure is being covered. The use of semi-mobile scanning in the MAUS has been the first step in the direction of full mobility.

INSPECTION CRAWLERS

Scanning an aircraft using a portable bridge configuration has been an effective step in addressing the need for automatic field testing capability. However, the constraint to covering an area only within the bounds of the scanner bridge has limited the operation speed, the accessibility to complex areas (particularly near joint with a wing, etc.) and required scaffolding to allow sequential attachment of the bridge to different locations. Mobile scanners can greatly increase the rate of inspection, minimize human errors and offer flexibility of reaching various areas of the aircraft. These scanners need to have a controlled adherence capability to maintain attachment to the structure surface while traveling and inspecting it. Such scanners, in the form of crawlers, are increasingly emerging as a solution to the need for unconstrained mobility and dexterity while conducting automatic scanning. The use of suction cups has become a leading form of controlled adherence to aircraft surfaces and several successful scanners have developed in the last several years. The Automated Non Destructive Inspector (ANDI) and the Autocrawler are some of the more known mobile scanners [Bar-Cohen, 2000, Backes & Bar-Cohen, 1996, Bahr, 1992, and Siegel, et al, 1998]. In recognition of the need to have a compact, more maneuverable crawler, JPL recently developed a small, highly dexterous crawler so-called Multifunction Automated Crawling System (MACS). This crawler, which is shown in Figure 3, was designed to perform complex scanning tasks [Bar - Cohen, et al, 1999] taking advantage of its ability to easily turn or move forward and

backward while being attached to a curved surface. MACS employs ultrasonic motors for mobility and suction cups for surface adherence. It has two legs for linear motion, with one leg serving as the rotation element for turning (see Figure 4). This mobility configuration allows performing any simultaneous combination of motion, including linear travel as well as rotation around the central axis. MACS can be applied to inspecting composite and metallic structures for detection of cracks, corrosion, impact damage, unbonds, delaminations, fire damage, porosity and other flaws, as well as paint thickness measurement. Also, this crawler can be designed to identify dents and individual fasteners.

Figure 3: MACS crawling on the C-5 aircraft
[Bar -Cohen, et al, 1999].



The development of MACS was benefited from the ongoing JPL development of miniature planetary rovers, as demonstrated by the Mars Pathfinder Mission, as well as telerobotic and NDE techniques. MACS was developed to serve as a generic robotic platform that can be used for many applications, including inspection, paint removal and painting of ships as well as testing/maintaining aircraft. Having many users is expected to lead to lower cost systems that will be improved by a large pool of users and developers. The monitoring of MACS activities can be designed for local control or control via the Internet with password access. A standard PC architecture will enable rapid implementation of new sensors, which can be easily integrated into the setup. To define the crawler functions, plug-and-play boards will need to be developed and thus enable a new NDE industry that can rapidly introduce novel products as well as transfer technology to commercial use. The JPL's telerobotic program and extensive planetary exploration experience with rover technology are providing a valuable resource to this emerging and enabling technology.

The ability to crawl on surfaces has been enabled by use of suction cup elements that are extended at the stage of attachment. An air pressure in the range of 80 to 120-psi, as can be obtained from conventional pressure lines is used to eject the suction cups onto the test surface at the moment that the specific leg is made to adhere to the surface. Individual venturi pumps provide each suction cup with sufficient vacuum to assure effective attachment. The ability to adjust the ejection distance of the individual rods allows the crawler to travel on curved surfaces. The smallest diameter of the curved surface, which

can be inspected by MACS, depends on the suction cups total ejection length and the size of the crawler platform.

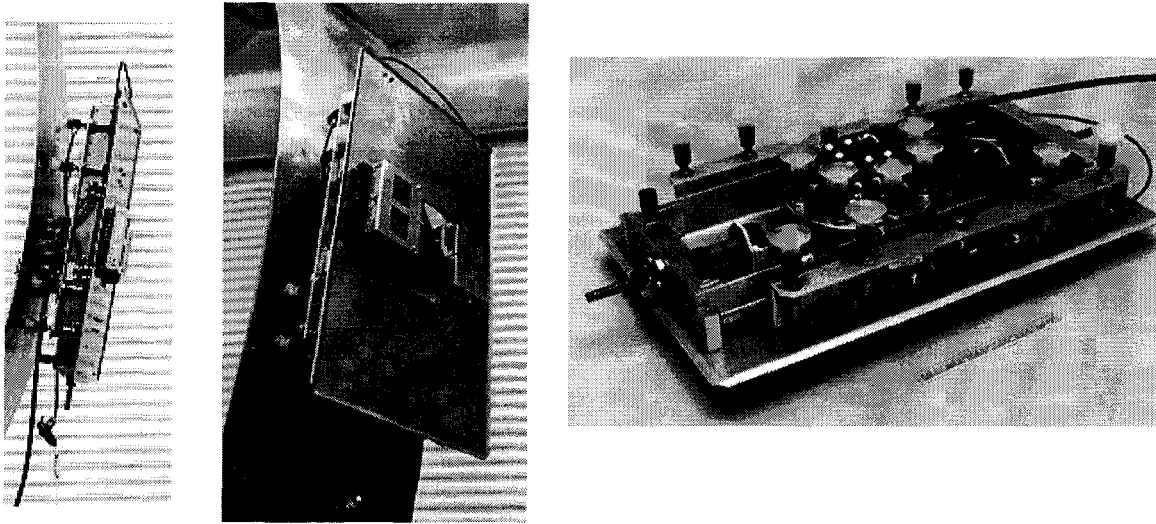


Figure 4: A photographic view of MACS from difference angles, where the two legs and the crawler ability to be attached to a curved surface are shown.

AUTONOMOUS CRAWLERS USING INTELLIGENT NDE

Autonomous operation of NDE crawlers can make a significant impact on the future of field inspection of complex structures, such as aircraft. An autonomous crawler can be monitored remotely by centrally located experts that are equipped with know-how, database, analytical tools, CAD drawing, and accept/reject criteria. Such a capability will allow rapid response to inspection needs, particularly in cases of crisis where it is necessary to examine a full flight of a particular aircraft model worldwide. An autonomous crawler can be operated during aircraft idle time, including night shift, reducing the need to remove an aircraft from service for inspection. Sensors that are based on visual, eddy current and ultrasonic NDE methods are expected to serve as key inspection tools on future autonomous crawlers. Autonomous robotic technology is currently being studied in numerous areas and at JPL it is being considered for planetary exploration, where the Mars Pathfinder already enjoyed some of its benefits. Miniature robotic technologies with on-board intelligence are being developed for future missions allowing a rover to examine, select and collect planetary samples while avoiding obstacles during operation in an unknown terrain. Since communication between Earth and various planets takes several minutes or more each way, the need for autonomous operation rather than a direct remote control is critical to the success of such NASA missions. The JPL's crawler MACS currently uses an umbilical cord for power, communication/control and to provide air pressure for the ejection and activation of the vacuum suction cups. Follow-on efforts are expected to minimize the content of the cord to a safety cable, power and communication. Potential future development will reduce the content further to the level of only safety cable with a miniature on-board pressure pump, power, wireless communication, and computing capability. Progress in the field of miniature-electro-mechanical system (MEMS) is expected to greatly benefit the inspection crawler technology.

Crawlers can employ local Global Positioning Systems (GPS) and laser localization to determine the absolute coordinates. Further, such GPS systems can relate the location of the crawler on the aircraft to the detailed drawing and thus assist in the data interpretation for the determination of the acceptability or rejection of flaws as well as the necessary corrective action. To protect aircraft elements that rise above the surface from accidental damage, a vision system can be used in conjunction with collision avoidance software. Data fusion and neural network interpretation can be used to perform intelligent signal acquisition as well as flaw detection and characterization [Vazquez and Bar-Cohen, 1990].

PLATFORM FOR MINIATURE NDE INSTRUMENTS

The personal computer (PC) technology offers a model for smart mobile platforms, namely the establishment of the equivalent to the motherboard. Various companies are making boards and components for PC allowing them to concentrate on their strength and innovation, rather than having to produce a complete new system each time they launch a new product. As an example, manufacturers of an internet card or a modem can concentrate on improving their product or introduce a new board without having to make a complete personal computer. The key issue is that these companies can dedicate their capability to a well-defined product area. This it is possible due to the motherboard architecture standard to which they maintain compliance.

Crawlers can be developed as "walking computer", i.e. mobile platform, which can use a motherboard to which boards can be added to provide NDE, control, power, intelligence and communication capabilities. The crawlers can be produced by telerobotic companies, which will have standard bus architecture offering a plug-in capability for miniature NDE instruments. Such crawlers will allow the NDE industry to concentrate on making unique miniature instruments modules for plug-in onto the crawlers and making driver software for microprocessor control of the modules. This field is multidisciplinary and just as in the case of the PC technology it is very difficult for a single company to possess all the necessary expertise. This approach offers a larger pool of companies to contribute to the field as well as the ability to standardize the products for a larger user base and thus significantly reduce cost. The engineering side of the crawler technology involves the development of the platform components including the power supply, mainframe, bus and wireless communication, position tracking (local GPS, encoders, etc.), controlled attachment, actuators and motion control. In the area of NDE instruments miniaturization, the field is starting to see some progress but there is much work that needs to be done and more companies need to be involved. The JPL's MACS crawler can serve as a baseline technology for an industry standard. The micro-electronic mechanical systems (MEMS) technology will enable future generations of extremely small scanning NDE instrumentation.

The field of robotic crawlers for aircraft inspection is still relatively new and more development is needed before an autonomous crawler can become available for robotic inspection of aircraft structures [Bar-Cohen, 2000]. To accelerate the development, the principal author of this paper has taken an initiative with American Society for NDT

(ASNT) to have Sessions on Robotics Miniaturized NDT Instruments in each of the ASNT conferences since the '96 Fall Conference, which was held at Seattle, WA. Efforts are being made to nurture the growth of the pool of companies that are producing miniature instruments and modular plug-ins.

CONCLUSIONS

Automation made the greatest impact on many elements of our modern life as a result of enabling the production of extremely large number of affordable products with known performance specifications. When applied to NDE, the process can be done significantly faster, more reliably and at lower cost. The evolution of microelectronics, computers and the internet helped making superb automatic capabilities that can also be controlled remotely. Robotic systems represent an important element of automation, however compared to other fields that need automation the transition of robotics to NDE has been relatively slow. Generally, there is still some misconception perceiving robotics as an expensive and inapplicable to one-of-a-kind inspection requirements. In recent years, significant progress has been made in robotics and there is a growing recognition of the potential role that it can play as an effective inspection workhorse. Generally, automatic NDE minimizes human errors, increases the probability of detecting flaws, can be operated at harsh environments and rapidly provides accurate data for quantitative NDE. Using computerized signal processing, NDE systems are now capable of handling extremely large number of replicate samples and related databases at unprecedented speed and efficiency. Such systems significantly increased the reliability of NDE and they are improved continuously with the evolution of the technology.

The recently developed multifunction automated crawling system (MACS) offered enabling technology of simultaneously using several NDE methods that are operated by a single scanner. Such a crawler can travel on an aircraft structure and automatically perform inspection tasks that can be controlled remotely over a modem or the Internet. Effectively, MACS is a robotic platform which can be used to integrate a suite of sensors and to perform intelligent scanning and testing aircraft for corrosion and other defects. The most attractive feature of this scanner is its open-architecture potential allowing to emulate the success of the personal computers. Crawlers can be made at significantly more affordable by employing commercially available components while allowing the NDE industry to concentrate on making dedicated sensor modules as plug-and-play boards. As the technology evolves, particularly in the area of planetary rovers in space exploration, crawlers would be developed to operate autonomously and search for flaws on aircraft structures without human interference.

ACKNOWLEDGMENT

The development of MACS was done by the Jet Propulsion Laboratory, California Institute of Technology under contract #FD2050-95-64062 with the Air Force Material Command, Kelly Air Force Base through an agreement with the National Aerospace Space Administration (NASA).

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